entirety and insert between line 1 and line 2, the following equation:

a12

Osin = ½·{ [Ucos(1)-Ucos(3)] + [(Usin(2)-Usin(1))·(Usin(2)+Usin(1))/(Ucos(2)-Ucos(1))] -
[(Usin(3)-Usin(2))·(Usin(3)+Usin(2))/(Ucos(3)-Ucos(2))] }/{ [(Usin(2)-Usin(1))/(Ucos(2)-Ucos(1))]
- [(Usin(3)-Usin(2))/(Ucos(3)-Ucos(2))] },

Page 7, second equation, line 2, please delete the original equation or line 2 in its entirety and insert the following equation between line 2 and line 3:

a13

Ocos = ½·{ [Usin(1)-Usin(3)] + [(Ucos(2)-Ucos(1))·(Ucos(2)+Ucos(1))/(Usin(2)-Usin(1))] -
[(Ucos(3)-Ucos(2))·(Ucos(3)+Ucos(2))/(Usin(3)-Usin(2))] }/{ [(Ucos(2)-Ucos(1))/(Usin(2)-Usin(1))]
- [(Ucos(3)-Ucos(2))/(Usin(3)-Usin(2))] },

In the Abstract:

Please replace the original abstract with the following amended abstract:

Abstract

a14

A method of calibrating the offset of angle sensors, which determine an angle to be determined on the basis of a sine signal assigned to the angle and a cosine signal assigned to the angle. This method includes determining the sine signal and the cosine signal for at least three different angles to obtain at least three value pairs, each pair containing one sine signal value and one cosine signal value; displaying the at least three value pairs in an at least two-dimensional coordinate system that represents a sine signal-cosine signal plane and determining a point, representing the offset to be calibrated, in the COORDINATE ~~coordinate~~ system with regard to which point the at last three value pairs are located on an arc.

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